

CLAIMS

1. A process for displacing a moveable unit (4)
on a base (2), said moveable unit (4) being displaced
linearly according to a predetermined displacement under
5 the action of a controllable force (F),
wherein:

a) equations are defined which:

10 - illustrate a dynamic model of a system formed by
elements (2, 4, MA, MA1, MA2, MA3), of which said
moveable unit (4) is one, which are brought into motion
upon a displacement of said moveable unit (4); and
- comprise at least two variables, of which the
position of said moveable unit (4) is one;

15 b) all the variables of this system, together with said
force (F), are expressed as a function of one and the
same intermediate variable y and of a specified number
of derivatives as a function of time of this
intermediate variable, said force (F) being such that,
applied to said moveable unit (4), it displaces the
20 latter according to said specified displacement and
renders all the elements of said system immobile at the
end of said displacement;

c) the initial and final conditions of all said variables are determined;

d) the value as a function of time of said intermediate variable is determined from the expressions for the

5 variables defined in step b) and said initial and final conditions;

e) the value as a function of time of said force is calculated from the expression for the force, defined in step b) and said value of the intermediate variable,

10 determined in step d); and

f) the value thus calculated of said force (F) is applied to said moveable unit (4).

2. The process as claimed in claim 1,

wherein, in step a), the following operations are

15 carried out: the variables of the system are denoted x_i , i going from 1 to p , p being an integer greater than or equal to 2, and the balance of the forces and of the moments is expressed, approximating to first order if necessary, in the so-called polynomial matrix
20 form:

$$A(s)X = bF$$

with:

- $A(s)$ matrix of size $p \times p$ whose elements $A_{ij}(s)$ are polynomials of the variable $s = d/dt$;

- X the vector $\begin{pmatrix} x_1 \\ \vdots \\ x_p \end{pmatrix}$;

- b the vector of dimension p; and

- F the force exerted by a means of displacing the moveable unit and in that, in step b), the following

5 operations are carried out:

- the different variables x_i of said system, i going from 1 to p, each being required to satisfy a first expression of the form:

$$x_i = \sum_{j=0}^{i=r} p_{i,j} y^{(j)} ,$$

10 the $y^{(j)}$ being the derivatives of order j of the intermediate variable y , r being a predetermined integer and the $p_{i,j}$ being parameters to be determined, a second expression is obtained by putting $y^{(j)} = s^j \cdot y$:

15
$$x_i = \left(\sum_{j=0}^{i=r} p_{i,j} s^j \right) y = P_i(s) \cdot y ,$$

- a third expression of vectorial type is defined on the basis of the second expressions relating to the different variables x_i of the system (S_1, S_2):

$$X = P \cdot y$$

comprising the vector $P = \begin{pmatrix} P_1 \\ \vdots \\ P_p \end{pmatrix}$

- said vector P is calculated, by replacing X by the value P.y in the following system:

$$\begin{cases} B^T.A(s).P(s) = O_{p-1} \\ b_p.F = \sum_{j=1}^{j=p} A_{p,j}(s).P_j(s).y \end{cases}$$

5 in which:

- . B^T is the transpose of a matrix B of size $p \times (p-1)$, such that $B^T b = O_{p-1}$;

- . b_p is the p-th component of the vector b previously defined; and

10 . O_{p-1} is a zero vector of dimension (p-1);

- the values of the different parameters $p_{i,j}$ are deduced from the value thus calculated of the vector P; and

15 - from these latter values are deduced the values of the variables x_i as a function of the intermediate variable y and of its derivatives, on each occasion using the corresponding first expression.

3. The process as claimed in claim 1,

wherein, in step d), a polynomial expression for the intermediate variable y is used to determine the value of the latter.

4. The process as claimed in claim 3,

5 wherein, the initial and final conditions of the different variables of the system, together with the expressions defined in step b), are used to determine the parameters of the polynomial expression for the intermediate variable y.

10 5. The process as claimed in claim 1 for displacing a moveable unit (4) on a base (2) which is mounted elastically with respect to the floor (S) and which may be subjected to linear and angular motions, wherein the variables of the system are the linear
15 position x of the moveable unit, the linear position xB of the base and the angular position θz of the base, which satisfy the relations:

$$\begin{cases} x = y + \left(\frac{r_B}{k_B} + \frac{r_\theta}{k_\theta} \right) y^{(1)} + \left(\frac{m_B}{k_B} + \frac{r_B r_\theta}{k_B k_\theta} + \frac{J}{k_\theta} \right) y^{(2)} + \left(\frac{r_B J}{k_B k_\theta} + \frac{m_B r_\theta}{k_B k_\theta} \right) y^{(3)} + \frac{m_B J}{k_B k_\theta} y^{(4)} \\ x_B = - \frac{m}{k_B} \left(\frac{J}{k_\theta} y^{(4)} + \frac{r_\theta}{k_\theta} y^{(3)} + y^{(2)} \right) \\ \theta z = -d \frac{m}{k_\theta} \left(\frac{m_B}{k_B} y^{(4)} + \frac{r_B}{k_B} y^{(3)} + y^{(2)} \right) \end{cases}$$

in which:

- m is the mass of the moveable unit;
- m_B , k_B , k_θ , r_B , r_θ are respectively the mass, the linear stiffness, the torsional stiffness, the linear damping and the torsional damping of the base;
- 5 - J is the inertia of the base with respect to a vertical axis;
- d is the distance between the axis of translation of the center of mass of the moveable unit and that of the base; and
- 10 - $y^{(1)}$, $y^{(2)}$, $y^{(3)}$ and $y^{(4)}$ are respectively the first to fourth derivatives of the variable y .

6. The process as claimed in claim 1 for displacing on a base a moveable unit (4) on which are elastically mounted a number p of auxiliary masses MA_i ,
 15 p being greater than or equal to 1, i going from 1 to p ,

wherein the variables of the system are the position x of the moveable unit (4) and the positions z_i of the p auxiliary masses MA_i , which satisfy the relations:

$$\begin{cases} x = \left(\prod_{i=1}^p \left(\frac{m_i}{k_i} s^2 + \frac{r_i}{k_i} s + 1 \right) \right) \cdot y \\ z_i = \left(\prod_{\substack{j=1 \\ j \neq i}}^p \left(\frac{m_j}{k_j} s^2 + \frac{r_j}{k_j} s + 1 \right) \right) \cdot \left(\frac{r_i}{k_i} s + 1 \right) \cdot y \end{cases}$$

in which:

- Π illustrates the product of the associated expressions;

5 - m_i , z_i , k_i and r_i are respectively the mass, the position, the stiffness and the damping of an auxiliary mass MA_i ;

- m_j , k_j and r_j are respectively the mass, the stiffness and the damping of an auxiliary mass MA_j ; and

10 - $s = d/dt$.

7. The process as claimed in claim 1 for displacing a moveable unit (4) on a base (2) which is mounted elastically with respect to the floor (S) and on which is elastically mounted an auxiliary mass (MA),
 15 wherein the variables of the system are the positions x , x_B and z_A respectively of the moveable unit (4), of the base (2) and of the auxiliary mass (MA), which satisfy the relations:

$$\begin{cases} x = [(mAs^2 + rAs + kA).(mBs^2 + (rA + rB)s + (kA + kB)) - (rAs + kA)^2].y \\ xB = -My^{(2)} \\ zA = -M(rAy^{(3)} + kAy^{(2)}) \end{cases}$$

in which:

- M, mB and mA are the masses respectively of the moveable unit (4), of the base (2) and of the auxiliary

5 mass (MA);

- rA and rB are the dampings respectively of the auxiliary mass (MA) and of the base (2);

- kA and kB are the stiffnesses respectively of the auxiliary mass (MA) and of the base (2); and

10 - $s = d/dt$.

8. The process as claimed in claim 1 for displacing on a base mounted elastically with respect to the floor, a moveable unit on which is elastically mounted an auxiliary mass,

15 wherein the variables of the system are the positions x, xB and zC respectively of the moveable unit, of the base and of the auxiliary mass, which satisfy the relations:

$$\begin{cases} x = [(mCs^2 + rCs + kC).(mBs^2 + rBs + kB)].y \\ xB = [(mCs^2 + rCs + kC).(Ms^2 + rCs + kC) - (rCs + kC)^2].y \\ zC = (rCs + kC).(mBs^2 + rBs + kB).y \end{cases}$$

20 in which:

- M, mB and mC are the masses respectively of the moveable unit, of the base and of the auxiliary mass;
- rB and rC are the dampings respectively of the base and of the auxiliary mass;
- 5 - kB and kC are the stiffnesses respectively of the base and of the auxiliary mass; and
- $s = d/dt$.

9. A device comprising:

- a base (2);

- 10 - a moveable unit (4) which may be displaced linearly on said base (2); and
- a controllable actuator (5) able to apply a force (F) to said moveable unit (4) with a view to its displacement on said base (2),

- 15 wherein it furthermore comprises means (6) which implement steps a) to e) of the process specified under claim 1, so as to calculate a force (F) which may be applied to said moveable unit (4), and which determine a control command and transmit it to said actuator (5)
- 20 so that it applies the force (F) thus calculated to said moveable unit (4).